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Fig. 13 is a sectional view of another variant of the gear of Fig. 6.--

Page 6, please replace the paragraph starting at line 12 and ending at line 23 with the following new paragraph:

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--The gear shaft 3 is mounted by means of antifriction bearings, e.g. ball bearings 5 in the gearbox 4. In order to remove the movement of the gearbox 4 with respect to the gear shaft 3 on the side 3b of said shaft 3 remote from the gearbox 4, the latter has a shaft 15, which traverses the gear shaft 3 and is connected in non-rotary manner to the gearbox 4. For transmitting the torque of the in particular high speed side drive shaft 7 is provided a gearwheel 16 located thereon and which meshes with a gearwheel 17 mounted in rotary manner on the gearbox 4, which in turn is in engagement with a gearwheel 18 connected in non-rotary manner to the gear shaft 3. Planet wheel 18 further on meshes with an internal gear 19 formed on the interior wall of the gearbox 4. The gearwheels 16, 17, 18 make it possible to increase the torque of the drive motor 6 and bridge the eccentric arrangement of its drive shaft 7 with respect to the gear axis 2.--

Page 7, after the paragraph starting at line 35 and ending at line 37, please add the following new paragraphs:

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--Fig. 10 shows details from the basic embodiment depicted in previously discussed Fig. 2. The drive shaft 7 has a worm gear in its end portion 7a that meshes with a worm gear formed in an upper area 3c of the gear shaft 3.

Fig. 11 shows details from another embodiment derived from the basic embodiment depicted in Fig. 2. The embodiment of Fig. 11 differs from the embodiment shown in Fig. 10, in that the drive shaft 7 comprises a bevel pinion 7b which meshes with a bevel gear formed in an area 3d of the gear shaft 3.

The embodiment shown in Fig. 12 differs from the embodiment in Fig. 6, in that the gear shaft 3 comprises an eccentric shaft 20 in connection with gearwheel 18. The eccentric shaft 20 drives a carrier pinion 21 which rolls off in an internal geared wheel 22. Differing gear tooth numbers on the carrier pinion 21 and the internal geared wheel 22 lead to relative movement between the two which is transmitted to the gear shaft 3 by means of eccentric bearings 23.

The embodiment of Fig. 13 differs from that in Fig. 6 and Fig. 12, in that there is no gearwheel 18. Instead gearwheel 17 comprises a wave generator 17a, i.e. an ellipsoidally shaped wheel which deforms a toothed flexible spine 24 for meshing an internal gear 25 provided on the gear shaft 3 of the harmonic drive.--

IN THE CLAIMS:

Please replace claim 1 as follows.

1. (Amended) Gear for a robot having a drive shaft and at least two first and second parts rotatable relative to the drive shaft and to one another, in which a movement of the first part is removable on a first end side remote from the second part, characterized in that at least